EAST Search History

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	2	JP-2000288974-$.did.	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L2	2	JP-2000288968-$.did.	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L3	1	JP-04075887-$.did.	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L4	2	WO-9942257-$.did.	US-PGPUB; USPAT; EPO; JPO; DERWENT	OR	ON	2006/11/20 10:06
L5	2	WO-9201539-$.did.	US-PGPUB; USPAT; EPO; JPO; DERWENT	OR	ON	2006/11/20 10:06
L6	6	"5083073".pn. "5446835".pn. "5523663".pn. "4725965".pn. "4985846".pn. "5297238".pn.	US-PGPUB; USPAT	OR	ON	2006/11/20 10:06
L7	1	("5,617,335").PN.	US-PGPUB; USPAT; USOCR	OR	OFF	2006/11/20 10:06
L8	1	("4,727,471").PN.	US-PGPUB; USPAT; USOCR	OR	OFF	2006/11/20 10:06
L9	5	JP-05127722-$.did. JP-07270137-$.did. JP-07319525-$.did.	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L10	1	("4785528").PN.	US-PGPUB; USPAT; USOCR	OR	OFF	2006/11/20 10:06
L11	279	(382/152).CCLS.	US-PGPUB; USPAT; USOCR	OR	OFF	2006/11/20 10:06
L12	44	((382/152).CCLS.) and robot	US-PGPUB; USPAT	OR	ON	2006/11/20 10:06

L13	80	((382/151).CCLS.) and robot	US-PGPUB; USPAT	OR	ON	2006/11/20 10:06
L14	11	arimatsu-taro.in.	US-PGPUB; USPAT	OR	ON	2006/11/20 10:06
L15	256	watanabe-atsushi.in.	US-PGPUB; USPAT	OR	ON	2006/11/20 10:06
L16	10	382/141-154;901/47.ccls. and watanabe-atsushi.in.	US-PGPUB; USPAT	OR	ON	2006/11/20 10:06
L17	131	(robot) same (plural$3 or multiple or dual or two or several or many) adj (video or camera or CCD or image or visual) same (workpiece or work-piece or work adj piece or part or model)	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L18	19	((382/154).CCLS.) and (reference or register$3 or registration or teach$3 or train$3 or learn$3) with (object or model or part or workpiece or work-piece or work adj piece) same robot	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L19	161	(robot) same (video or camera or CCD or image or visual) same (predetermined or known or specifi$2 or determined) near distance	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L20	80	robot same (2-D or two-D or two-dimension$2 or "2"-dimension$2 or bi-dimensional or (two or "2") adj dimension$2) with distance	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L21	37	robot same (reference or register$3 or registration or teach$3 or train$3 or learn$3) same (video or camera or CCD or image or visual) same (predetermined or known or specifi$2 or determined) near distance	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L22	72	((901/47).CCLS.) and (registration or teach$3 or train$3 or learn$3) with (model or part or workpiece or work adj piece)	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L23	209	(382/153).CCLS.	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2006/11/20 10:06

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L24	263	("382"/$.ccls. "348"/$.ccls. "356"/$.ccls. "700"/$.ccls. "901"/$.ccls.) and robot$3 same (camera or CCD or imag$3 or video) same (position$3 or locat$4 or (three or "3") adj dimension$2 or 3D or coordinate) with (orientation or posture or attitude or pose) with (object or workpiece or work adj piece or part or bin or pile$1 or article or body)	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06
L25	65	robot$3 same (camera or CCD or imag$3 or video) same (orientation or posture or attitude or pose) with (object or workpiece or work adj piece or part or bin or pile$1 or article or body) same (reference or model or register$3 or registration or template or stored) with (compar$5 or match$3 or correlat$3 or correspond$3)	US-PGPUB; USPAT; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/11/20 10:06

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L1	0	(robot and (determine near orientation) and (reference near model) and (capturing near direction)).clm.	US-PGPUB	OR	OFF	2006/11/20 10:19